

**IN THE CLAIMS:**

Claims 1-60 are canceled. Claims 61-77 are added. This listing of claims will replace all prior versions, and listings of claims in the application:

1-60. (Canceled)

61. (New) An electrosurgical instrument comprising:

a first body comprising;

a second body rotatably coupled to the first body;

a first effector and a second end effector rotatably coupled to the second body,

wherein the first and second end effectors each comprise a proximal portion and a distal portion,

wherein the proximal portions of the first and second end effectors

comprise a nonconductive body;

wherein the distal portions of the first and second end effectors comprise a substantially triangular shaped conductive grip body for gripping a target tissue;

a first lead coupled to the first end effector and a second conductive lead coupled to the second end effector,

wherein the first and second leads are attachable to a power source to deliver energy to the distal portions of the first and second end effectors.

62. (New) The electrosurgical instrument of claim 61 wherein the first body comprises a robotic manipulator interface.

63. (New) The electrosurgical instrument of claim 61 wherein the second body is rotatably coupled to the first body about a first axis, and the end effectors are rotatably coupled to the second body about a second axis,

wherein the first axis and second axis are substantially orthogonal to each other.

64. (New) The electrosurgical instrument of claim 63 wherein a third axis extends longitudinally down the first body, wherein the first body, second body and end effectors are rotatable about the third axis.

65. (New) The electrosurgical instrument of claim 61 wherein the triangular shaped conductive grip body on the first end effector and the second end effector each comprise an opening.

66. (New) The electrosurgical instrument of claim 61 wherein the nonconductive body surrounds the proximal portion of the end effector to insulate the first end effector from the second end effector.

67. (New) The electrosurgical instrument of claim 61 wherein the substantially triangular shaped conductive grip bodies comprise teeth.

68. (New) The electrosurgical instrument of claim 61 wherein the second body comprises a pulley assembly,  
wherein a plurality of drive cables interact with the pulley assembly and the non-conductive bodies to move the second body and the first and second end effectors.

69. (New) The electrosurgical instrument of claim 61 wherein the first lead is coupled to the proximal portion of the first end effector and is received within the nonconductive body of the first end effector and the second lead is coupled to the proximal portion of the second end effector and is received within the nonconductive body of the second end effector.

70. (New) An electrosurgical instrument comprising:  
a first body;  
a second body rotatably coupled to the first body;  
a first effector and a second end effector rotatably coupled to the second body,  
wherein the first and second end effectors each comprise a proximal portion and a distal portion,

wherein the proximal portions of the first and second end effectors comprise a nonconductive body;

wherein the distal portions of the first and second end effectors comprise a conductive grip body that comprises an opening therethrough;

a first lead coupled to the first end effector and a second conductive lead coupled to the second end effector,

wherein the first and second leads are attachable to a power source to deliver energy to the distal portions of the first and second end effectors.

71. (New) The electrosurgical instrument of claim 70 wherein the proximal end of the first body comprises a robotic manipulator interface.

72. (New) The electrosurgical instrument of claim 70 wherein the second body is rotatably coupled to the first body about a first axis, and the end effectors are rotatably coupled to the second body about a second axis,

wherein the first axis and second axis are substantially orthogonal to each other.

73. (New) The electrosurgical instrument of claim 70 wherein a third axis extends longitudinally down the first body, wherein the first body, second body and end effectors are rotatable about the third axis.

74. (New) The electrosurgical instrument of claim 70 wherein the nonconductive body surrounds the proximal portion of the end effector.

75. (New) The electrosurgical instrument of claim 70 wherein the conductive grip bodies comprise teeth.

76. (New) The electrosurgical instrument of claim 70 wherein the second body comprises a pulley assembly, wherein a plurality of drive cables interact with the pulley assembly and non-conductive body to move the first and second end effectors and second body.

77. (New) The electrosurgical instrument of claim 70 wherein the first lead is coupled to the proximal portion of the first end effector and is received within the nonconductive body of the first end effector and the second lead is coupled to the proximal portion of the second end effector and is received within the nonconductive body of the second end effector.